

Dyn<sub>2</sub>

FIG. 35

412

Dyn<sub>1</sub>

412

 $\overline{U(t)}$ 

 $\mathsf{Dyn}_{\,\mathbf{M}}$ 

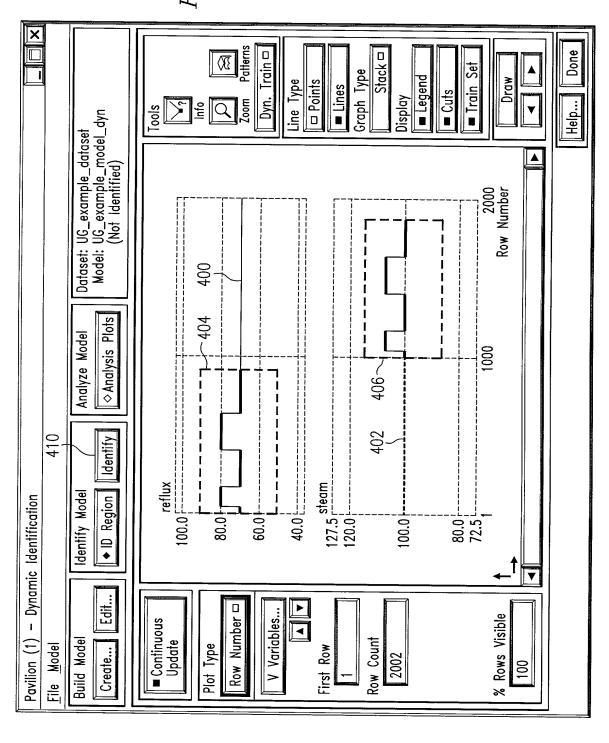
412

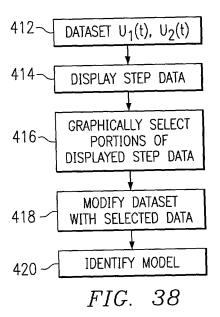
DKT. NO.: PAVI-25,964
TITLE: A METHOD FOR OPTIMIZING A PLANT WITH MULTIPLE INPUTS
INVENTORS: John P. Havener, Stephen Piche,
Donald Semrad and Brian K. Stephenson

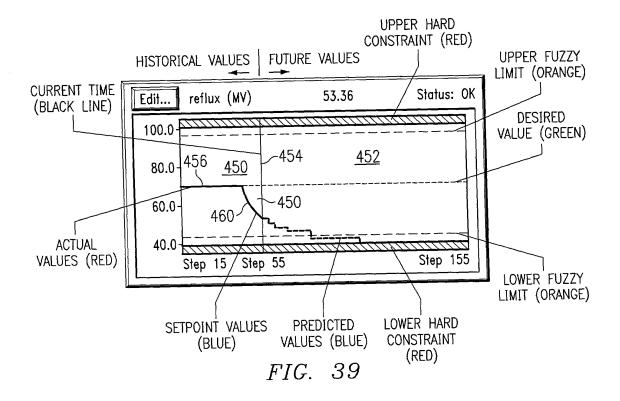
12/25

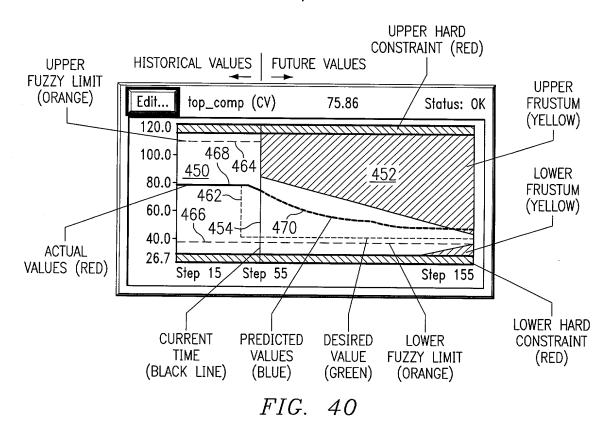
37

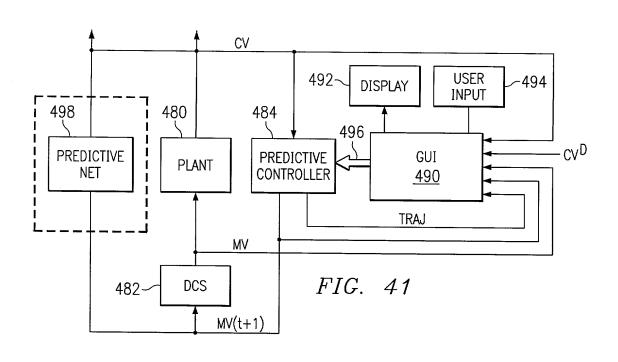
FIG.











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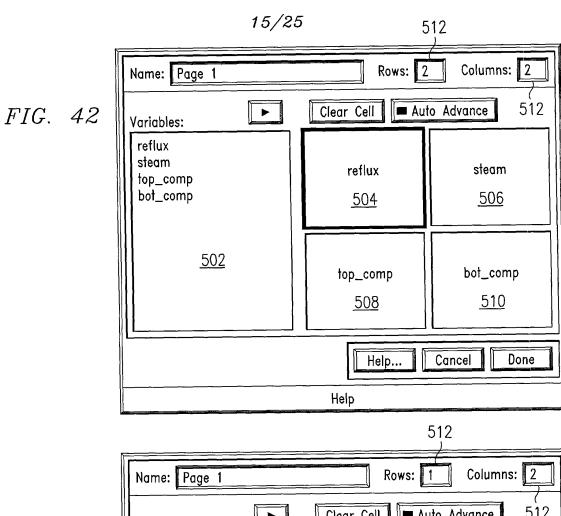
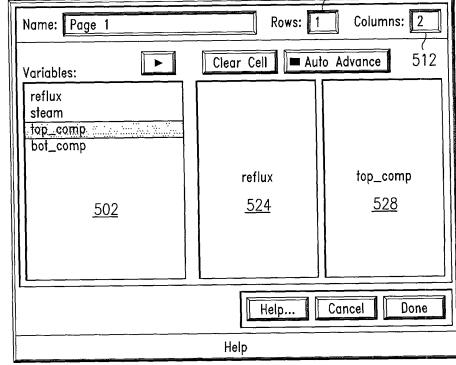
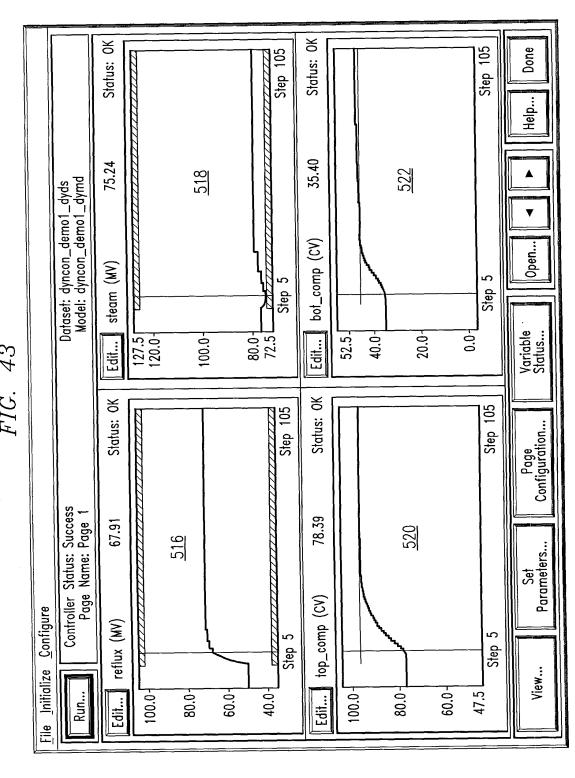


FIG. 44

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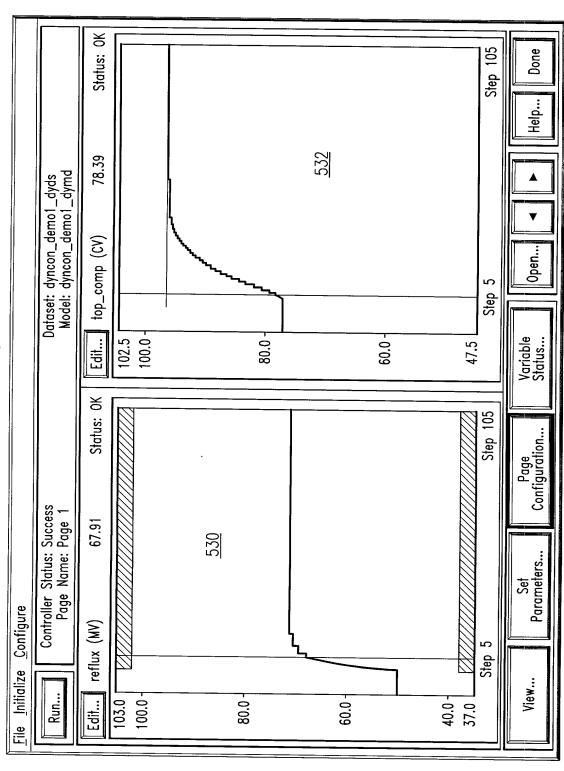
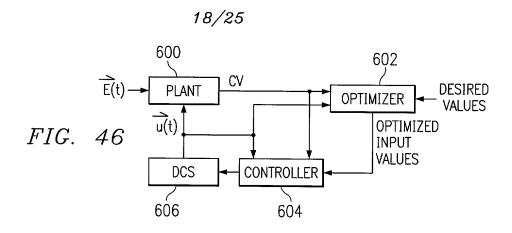
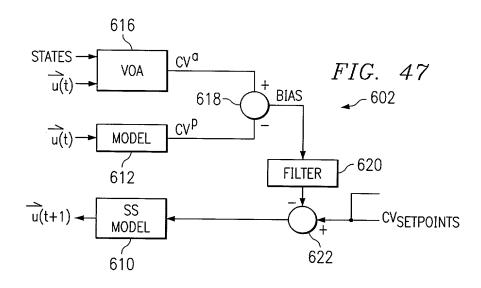
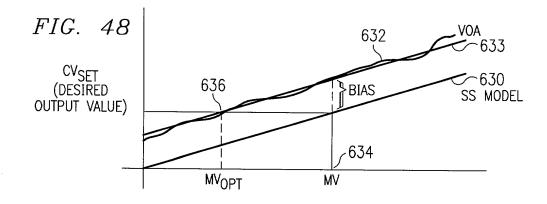
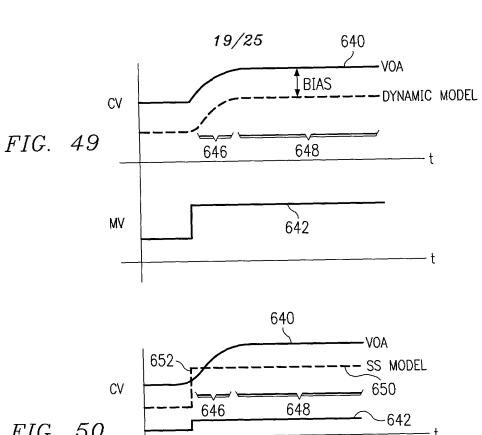


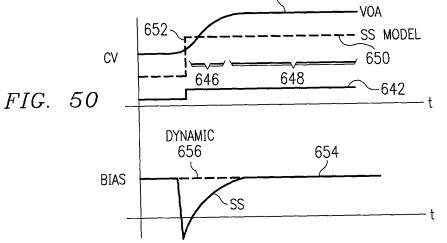
FIG. 45

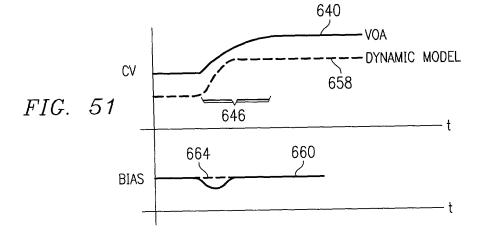


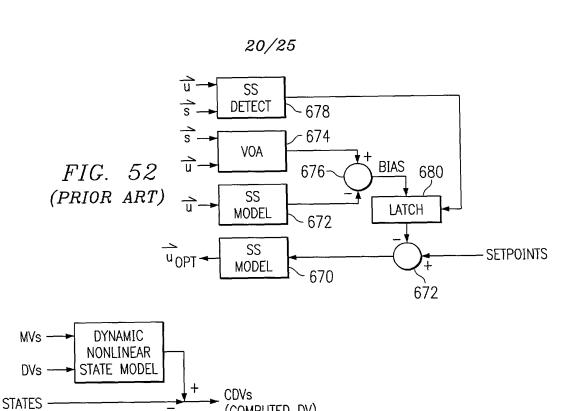












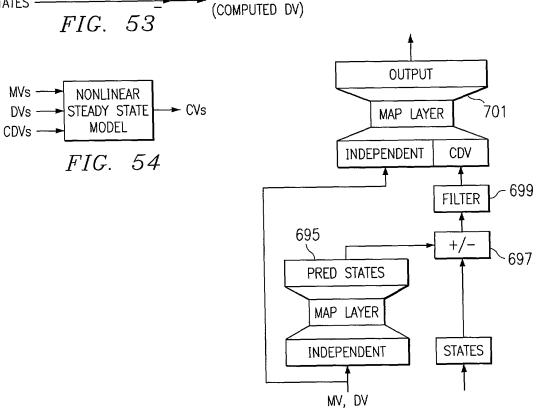
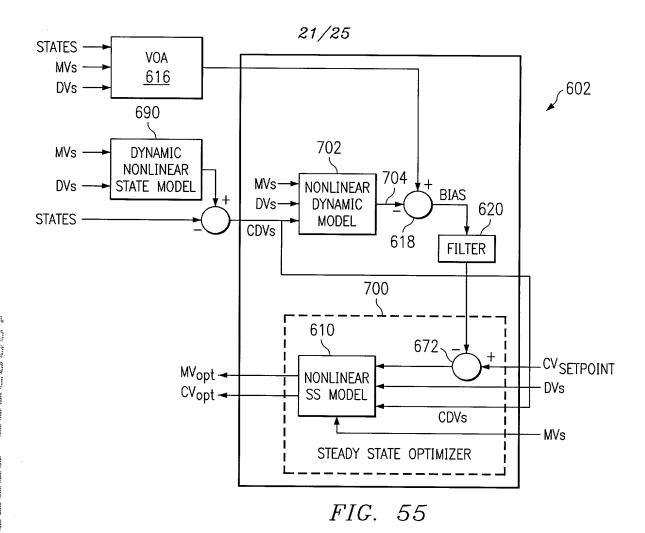
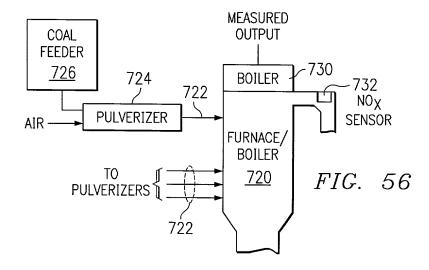
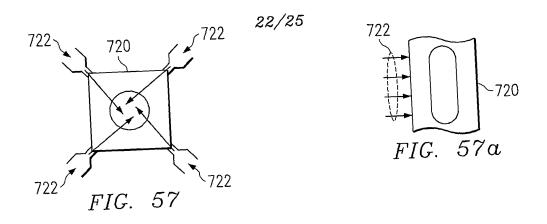


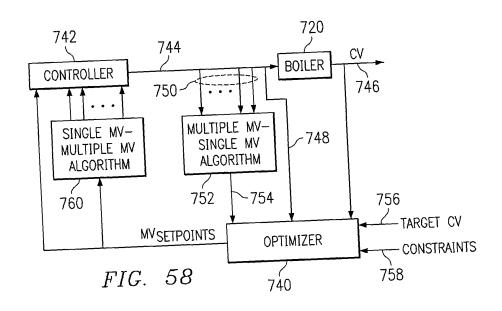
FIG. 53α

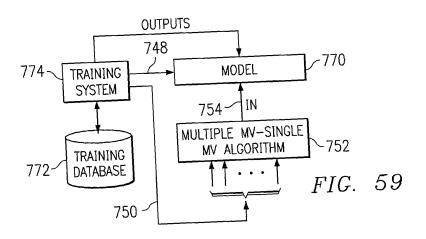
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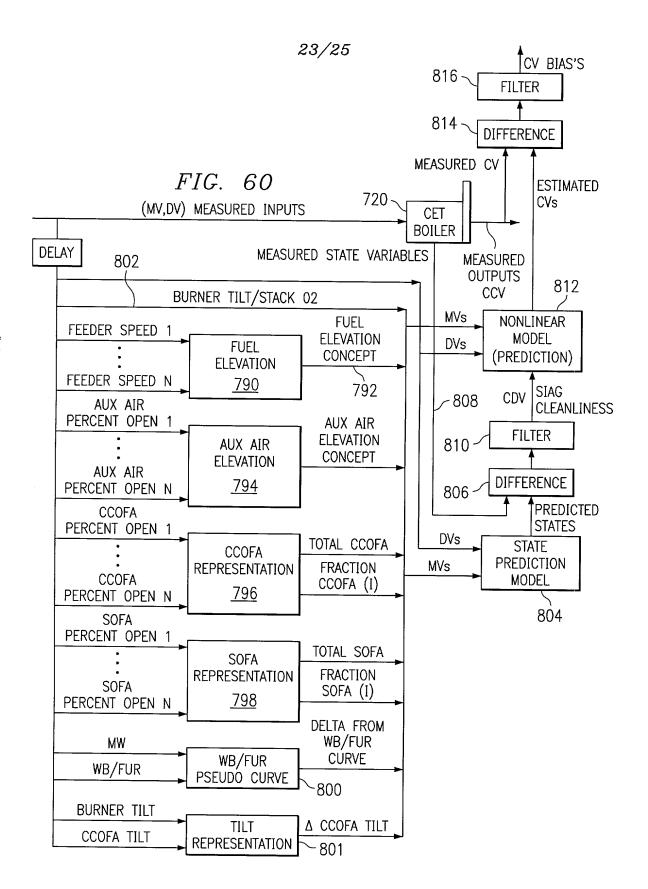


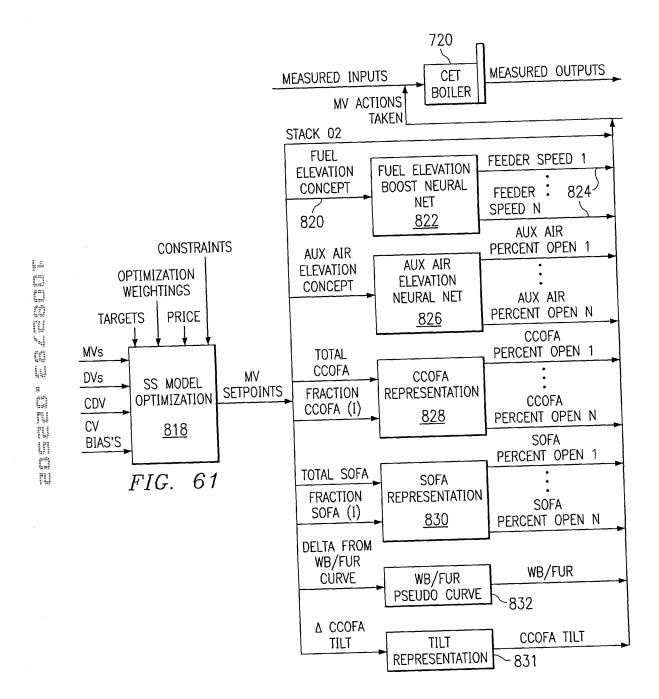


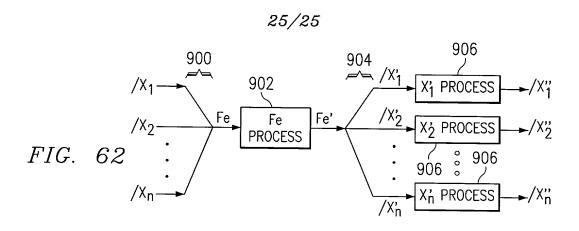


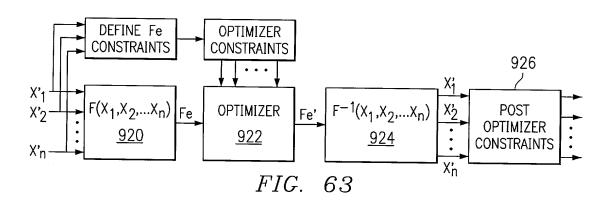












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